

CLAIMS

1. A legged mobile robot equipped with articulated legs such that it moves by driving each leg by an actuator associated therewith:

characterized in that:

5 each leg has at least a first joint and a second joint located below the first joint in the gravitational direction; and

that the actuator that drives the second joint is located at least one of a position same as that of the first joint and a position above the first joint in the gravitational direction.

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2. The legged mobile robot according to claim 1, wherein at least one of an output shaft of the actuator that drives the second joint and an output shaft of a transmission element to which an output of the output shaft of the actuator is transmitted, is located coaxially with an axis of the first joint, and the second joint is connected to the output shaft located coaxially with the axis of the first joint to be driven through a rod.

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3. The legged mobile robot according to claim 1 or 2, wherein the second joint has rotation axes that are arranged in at least two different directions.

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4. The legged mobile robot according to one of claims 1 to 3, wherein the second joint is driven by a plurality of actuators and is connected to at least one of output shafts of the actuators and output shafts of transmission elements to which outputs of the output shafts of the actuators are transmitted, to be driven through a plurality of rods.

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5. The legged mobile robot according to claim 4, wherein the rods are located to be spaced by prescribed distances from axes of the second joints.

5 6. The legged mobile robot according to one of claims 1 to 5, wherein the second joint is one among the joints that the legs have, that is located farthest toward a ground-contacting end.